

Amendments to the Claims:

This listing of claims will replace all prior versions, and listings, of claims in the application:

Listing of Claims:

1. (Currently Amended) A method for performing a surgical procedure with a robotic surgical system comprising:

providing a plurality of surgical instrument assemblies each comprising a wrist unit having a shaft with a proximal end and a distal wrist, and an instrument removably coupled to the distal wrist;

connecting the proximal end of the wrist unit shaft of one of the surgical instrument assemblies to a manipulator arm;

positioning the manipulator arm by articulating a mounting joint;

fixing the orientation of the mounting joint during the surgical procedure; and

introducing the instrument of said one of the surgical instrument assemblies to a treatment site on a patient with the manipulator arm.

2. (Original) The method of claim 1 further comprising removing the instrument of said one of the surgical instrument assemblies from the treatment site and disconnecting the proximal end of the wrist unit shaft of said one of the surgical instrument assemblies from the manipulator arm.

3. (Original) The method of claim 1 further comprising connecting the proximal end of the wrist unit shaft of another one of the surgical instrument assemblies to the manipulator arm, and introducing the instrument of said another one of the surgical instrument assemblies to the treatment site with the manipulator arm.

4. (Original) The method of claim 1 further comprising pivoting the instrument about the distal wrist of the wrist unit shaft.

5. (Original) The method of claim 1 further comprising:
shielding the manipulator arm from the treatment site with a sterile drape;
| attaching a sterile adaptor to the manipulator arm through the sterile drape; and
attaching the proximal end of the wrist unit shaft of said one of the surgical
instrument assemblies to the sterile adaptor.

6. (Canceled)

7. (Canceled)

8. (Currently Amended) The method of claim 1 [[7]] further comprising a
non-sterile drive component comprising the arm, the non-sterile drive component being mounted
on the articulated mounting joint and supported by the articulated mounting joint, and wherein
the non sterile drive component moves while the articulated mounting joint moves.

9. (Previously Presented) The method of claim 1 wherein the articulated
mounting joint is coupled to a ceiling of an operating room.

10. (Previously Presented) The method of claim 1 wherein the articulated
mounting joint is coupled to a wall of an operating room.

11. (Canceled)
